

IN THE CLAIMS:

This listing of claims will replace all prior versions, and listings of claims in the application:

1. (Original) A robotic surgical system ~~including~~ comprising:
a surgical manipulator system having a manipulator movably supporting at least one surgical instrument with a plurality of degrees of freedom of movement;
a master controller workstation operatively associated with the manipulator to cause selective movement of the instrument in response to inputs from a system operator at the workstation; and
a selectively activatable repositioning system configured to interrupt the operative association between the workstation and the manipulator so that the surgical instrument ~~can be~~ is moved movable from one position to another while the master controller workstation is held in a substantially fixed position, and to reestablish the operative association with the master controller workstation after the surgical instrument has been repositioned.
2. (Original) The robotic surgical system of claim 1, wherein the input device is mounted to the manipulator and is configured so that the surgical instrument is movable while the input device is held, and wherein the repositioning system reestablishes the operative association when the input device is released.
3. (Original) The robotic surgical system of claim 1, wherein the surgical instrument comprises an image capture device.
4. (Original) The robotic surgical system of claim 1, wherein the surgical instrument comprises a surgical tool having an end effector configured to treat tissue.
5. (Original) A robotic surgical system comprising:

a surgical manipulator system having a moveable image capture device for capturing an image of a surgical site and at least one medical instrument having a plurality of degrees of freedom of movement;

a workstation having a display operatively connected to the image capture device to display the surgical site, at least one master control device operatively associated with the medical instrument to cause selective movement of the instrument in response to inputs to the master control device, and an image capture device control system operatively associated with the image capture device to cause selective movement of the image capture device; and

a selectively activatable repositioning system configured to interrupt the operative association between the image capture device control and the image capture device so that the image capture device ~~can be moved from one position to another~~ is repositionable while the master controller workstation is maintained in position and to reestablish the operative association with the master controller workstation after the image capture device has been repositioned.

6. ~~(Canceled) The robotic surgical system of claim 5 wherein the repositioning system is configured to realign the master control device with the image capture device after the image capture device has been repositioned.~~

7. (Previously presented) The robotic surgical system of claim 5 wherein the repositioning system is configure to inhibit the motion of the image capture device in at least one degree of freedom.

8. (Previously presented) The robotic surgical system of claim 7 wherein the image capture device is inhibited from rotating about its longitudinal axis.

9. (New) A robotic surgical system comprising:
a manipulator movably supporting at least one surgical instrument;

a controller comprising an input device, the controller operatively associated with the manipulator to cause selective movement of the instrument in response to inputs from an operator at the controller; and

a clutching assembly that is movable from a first mode to a second mode, wherein the clutching assembly in the first mode is configured to interrupt the operative association between the controller and the manipulator so that the one of the input device and the surgical instrument is moved from one position to another while the other of the input device and the surgical instrument is held in a substantially fixed position, and the clutching assembly in the second mode is configured to reestablish the operative association between the manipulator and the controller after the surgical instrument or input device has been repositioned.

10. (New) The system of claim 9 wherein the surgical instrument comprises an end effector.

11. (New) The system of claim 10 wherein the end effectors are maintained in a substantially fixed position when the clutching assembly is in the first mode.

12. (New) The system of claim 9 wherein the surgical instrument comprises an image capture device.

13. (New) The system of claim 9 wherein the clutching assembly in the first mode is configured to inhibit repositioning of one of the controller and the surgical instrument in at least one degree of freedom.

14. (New) The system of claim 13 wherein the at least one degree of freedom is a rotational degree of freedom.

15. (New) The system of claim 9 wherein the clutching assembly in the first mode is configured to allow for manual translational repositioning of the input device without

corresponding translational movement of the surgical instrument in at least one translational degree of freedom.

16. (New) The system of claim 9 wherein the clutching assembly in the first mode is configured to inhibit independent repositioning of the input device in at least one rotational degree of freedom.

17. (New) A robotic surgical system comprising:
a manipulator movably supporting at least one surgical instrument;
a controller comprising an input device, the controller operatively associated with the manipulator to cause selective movement of the instrument in response to inputs from an operator at the controller; and

clutching means movable from a first mode to a second mode, wherein the clutching means in the first mode is configured to interrupt the operative association between the controller and the manipulator so that the one of the input device and the surgical instrument is moved from one position to another while the other of the input device and the surgical instrument is held in a substantially fixed position, and the clutching means in the second mode is configured to reestablish the operative association between the manipulator and the controller after the surgical instrument or input device has been repositioned.